transmitted from the wireless communication antenna **48** to be received by the wireless communication terminal **46**.

[0055] The front camera **56** is for capturing an image in the front of the tractor **1**. The rear camera **57** is for capturing an image in the rear of the tractor **1**. The front camera **56** and the rear camera **57** are attached to the roof **5** of the tractor **1**. Video data captured by the front camera **56** and the rear camera **57** is transmitted from the wireless communication antenna **48** to the wireless communication terminal **46** by the wireless communication unit **40**. The wireless communication terminal **46** that has received the video data displays the contents on the display **31**.

[0056] The above-described vehicle speed sensor **53** is for detecting the vehicle speed of the tractor **1** and is provided on an axle between the front wheels **7** and **7**, for example. The data of a detection result obtained by the vehicle speed sensor **53** is output to the control unit **4**. Note that it is also possible that the vehicle speed of the tractor **1** is not detected by the vehicle speed sensor **53** but is calculated based on the moving time period of the tractor **1** in a predetermined distance based on the positioning antenna **6**. The steering angle sensor **52** is a sensor that detects the steering angle of the front wheels **7** and **7**. In the present embodiment, the steering angle sensor **52** is provided on an illustration-omitted kingpin provided on the front wheels **7** and **7**. The data of a detection result obtained by the steering angle sensor **52** is output to the control unit **4**. Note that a configuration in which the steering angle sensor **52** is provided on the steering shaft is also possible.

[0057] As illustrated in FIG. **3**, the wireless communication terminal **46** includes the display **31** and the touchscreen **32**. The wireless communication terminal **46** is a tablet terminal but can be a smartphone, a laptop PC, or the like. Note that, in a case of making the tractor **1** autonomously travel in a state where the user is on board the tractor **1**, it is also possible that the same function as the wireless communication terminal **46** is provided on the tractor **1** side (for example, the control unit **4**). The user can refer to and check the information displayed on the display **31** of the wireless communication terminal **46** (for example, information from the front camera **56**, the rear camera **57**, the vehicle speed sensor **53**, etc.). In addition, the user can operate the above-described touchscreen **32**, an illustration-omitted hardware key, or the like, so as to transmit a control signal (for example, a pause signal, etc.) for controlling the tractor **1** to the control unit **4** of the tractor **1**.

[0058] The wireless communication terminal **46** includes an illustration-omitted arithmetic device such as a CPU, a storage device such as a non-volatile memory, an input-output unit, etc. The storage device stores various kinds of programs, data related to travel paths, etc. The arithmetic device is capable of reading various kinds of programs from the storage device and executing the programs. By the cooperation of the above-described hardware and software, the wireless communication terminal **46** can be operated as the display control unit **33**, the farm field acquisition unit **34**, the travel path creation unit **35**, the reference auxiliary line creation unit (auxiliary line creation unit) **36**, the adjacent auxiliary line creation unit (auxiliary line creation unit) **37**, the auxiliary line selection unit **38**, and the selection processing unit **39** (specific processing will be described later).

[0059] The display control unit **33** creates display data to be displayed on the display **31** and controls the display contents as appropriate. For example, the display control unit **33** displays a predetermined monitoring screen, instruction screen, or the like on the display **31** while the tractor **1** is caused to autonomously travel along a travel path.

[0060] The farm field acquisition unit **34** acquires the position and shape of a target farm field in which the tractor **1** performs autonomous traveling from the storage device. The position and shape of the farm field are created based on the transition of the position information of the positioning antenna **6** when the tractor **1** is caused to travel along the periphery of the farm field. Note that it is also possible that, without causing the tractor **1** to actually travel, the user designates a range on a map displayed on the display **31** so that the position and shape of the farm field are created, for example. Further, although the information related to the farm field is stored in the wireless communication terminal **46** in the present embodiment, it is also possible that the information related to the farm field is stored in a server that is physically distant from the wireless communication terminal **46**. In this case, the farm field acquisition unit **34** acquires information related to the farm field from this server.

[0061] Here, with reference to FIG. **4**, a brief explanation is given of the farm field. The farm field includes a work area and a headland area. The work area is located in the central part of the farm field and is an area for performing work (the area of which the main purpose is to perform work). The headland area is located outside the work area and is an area to be used for properly performing work in the work area. For example, the headland area is used for moving the tractor **1** that has entered the farm field to the start position of work in the work area. In addition, the headland area is also used for turning the tractor **1** that has travelled straight in the work area. Further, in the present embodiment, the work is performed not only on the work area but also on the headland area. Specifically, the tractor **1** travels in the work area to perform the work, and then the tractor **1** travels in the headland area to perform the work.

[0062] The travel path creation unit **35** creates a travel path for performing the work in the work area. In the present embodiment, the travel path creation unit **35** creates the straight paths **71** and the turning paths **72** illustrated in FIG. **4**, based on various kinds of settings made by the user using the wireless communication terminal **46**. The straight paths **71** are parallel to one side (short side) of the farm field peripheral edge and the work area peripheral edge. The arrangement interval of the straight paths **71** corresponds to the value obtained by subtracting the overlap amount (the length indicating how much adjacent work ranges overlap in the vehicle width direction) from the work width W**1** or the value obtained by adding the work interval (the length indicating how much interval is provided between adjacent work ranges in the vehicle width direction) to the work width W**1**. Further, a turning path **72** is a path connecting straight paths **71** to each other. Although a turning path **72** connects adjacent straight paths **71** to each other in the present embodiment, it is also possible that a turning path **72** connects distant straight paths **71** to each other. Further, a turning path **72** of the present embodiment is a path on which the tractor **1** is caused to turn around by making a turn by 90 degrees, then traveling backward, then switching to forward traveling, and then turning again by 90 degrees, so that the tractor **1** reaches the next straight path **71**. However, instead of this type of turning path **72**, it is also possible to create a turning path on which the tractor **1** is caused to turn